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US 20030112661 A1	Writable tracking cells	20030619	365/185.03
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US 20030093392 A1	System for intelligent control based on soft computing	20030515	706/13
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US 20020142392 A1	Human melanocyte stimulating hormone receptor polypeptide and DNA	20021003	435/69.1
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it is convenient to introduce the concept of **Lyapunov** exponent. Let us consider the function  $g$  that

We propose an algorithm for combinatorial **optimization** where an explicit check for the repetition of

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quadratic correction term as the solution of a **Lyapunov** equation. Remarkably, this correction term can

in both continuous and combinatorial **optimization** (we refer the reader to [18] for an extensive

On the Nesterov-Todd direction in semidefinite **programming** M. J. Todd K. C. Toh y and R. H.

[singa.math.nus.edu.sg/~mattohk/papers/sdp.ps.Z](http://singa.math.nus.edu.sg/~mattohk/papers/sdp.ps.Z)

On The Nesterov-Todd Direction In Semidefinite Programming - Todd, Toh, Tütüncü (1996) (Correct) (77 citations)

quadratic correction requires the solution of a **Lyapunov** equation, but this can be solved explicitly and

and Applied Mathematics, SIAM Journal on **Optimization** 8 (1998) 769-796. Corresponding author.

On The Nesterov-Todd Direction In Semidefinite **Programming** #M. J. Todd K. C. Toh #And R. H. T

[ftp.orie.cornell.edu/pub/techreps/TR1154.ps.Z](http://ftp.orie.cornell.edu/pub/techreps/TR1154.ps.Z)

Advanced Gain-Scheduling Techniques For Uncertain Systems - Pierre Apkarian (1997) (Correct) (12 citations)

controllers is the search for adequate **Lyapunov** functions that establish stability and a [1]an elegant and solidly based branch of **optimization** theory [2, 3, 4]Expressed in terms of Linear

using available tools in convex semi-definite **programming**. When used together, these techniques provide

[momiji94.ces.kyutech.ac.jp/apkarian/ACC97FULL.ps](http://momiji94.ces.kyutech.ac.jp/apkarian/ACC97FULL.ps)

Constraint Aggregation Principle in Convex Optimization - Ermoliev, Kryazhinskii.. (1995)  
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prove a simple lemma which is an analog of the **Lyapunov** function approach in the study of convergence of

Constraint Aggregation Principle in Convex **Optimization** Yuri M. Ermoliev Arkadii V. Kryazhinskii

in various application areas, like stochastic **programming** problems with constraints that have to hold

[www.iiasa.ac.at/Publications/Documents/WP-95-015.ps](http://www.iiasa.ac.at/Publications/Documents/WP-95-015.ps)

Constraint Programming in Constraint Nets - Zhang (1993) (Correct) (5 citations)

the process. Monotonicity" is characterized by a **Liapunov** function, representing the "distance" to the set

approach has been taken in neural nets [18]**optimization**, graphical simulation [16] and robot control

Constraint **Programming** in Constraint Nets Ying Zhang Department of

[ftp.cs.brown.edu/pub/ppcp93/zhang.ps.Z](ftp://cs.brown.edu/pub/ppcp93/zhang.ps.Z)

Value Iteration and Optimization of Multiclass Queueing Networks - Chen, Meyn (1997)

(Correct) (5 citations)

algorithm is initialized with a stochastic **Lyapunov** function, then the following hold i)A

Value Iteration and **Optimization** of Multiclass Queueing Networks Rong-Rong decision processes, optimal control, dynamic **programming**. Work supported in part by NSF Grant ECS

[black.csl.uiuc.edu/~meyn/vi.PS](http://black.csl.uiuc.edu/~meyn/vi.PS)

The Computational Power of Discrete Hopfield Nets with Hidden Units - Orponen (1996)

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with symmetric interconnections possess natural **Liapunov** functions, and are thus at least dynamically 1

from the general theory of local search for **optimization** problems (Schaffer and Yannakakis 1991)In

Colloquium on Automata, Languages, and **Programming**, Lecture Notes in Computer Science Vol. 700,

[www.math.jyu.fi/~orponen/papers/hoppow.ps](http://www.math.jyu.fi/~orponen/papers/hoppow.ps)

On Dynamically Consistent Hybrid Systems - Peter Caines (1995) (Correct) (2 citations)

control function to the next one. Motivated by **Liapunov** stability theory, M. Glaum [4] related algebraic

Further, in their recent work (6][7]an **optimization** problem (with ffl-tolerance) is converted into

(with ffl-tolerance) is converted into a linear **programming** problem based upon the discrete topology. In

<ftp://mcrcim.mcgill.edu/pub/papers/1995/hybrid1.ps.gz>

A Parameter-Dependent Performance Criterion for Linear.. - Lee, Spillman (1997)

(Correct) (2 citations)

such method uses parameter-dependent quadratic **Lyapunov** functions and ideas drawn from H1 **optimization**

theory, the synthesis problem reduces to convex **optimization** involving linear matrix inequalities. A

and optimizing controllers reduces to convex **programming**. These controllers are also systematically

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Approximate Solutions to the Time-Invariant.. - Beard, Saridis, Wen (1998) (Correct)  
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to successive approximations of a sequence of **Lyapunov** equations. In Ref. 9 the bilinear control

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control problem in the form of a nonlinear **programming** problem. The method is formulated in path

[www.ee.byu.edu/~beard/papers/jota98.ps](http://www.ee.byu.edu/~beard/papers/jota98.ps)

Nonlinear Optimal Control: A Control Lyapunov Function.. - Primbs, Nevistic, Doyle (1999)  
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Nonlinear Optimal Control: A Control **Lyapunov** Function and Receding Horizon Perspective James

viewpoint and is more suited to trajectory **optimization**. Consider the following problem: inf equations A standard dynamic **programming** argument reduces the above optimal control

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Infeasibility Handling In Linear Mpc Subject To.. - Vada, Slupphaug, Foss (1999) (Correct)  
(1 citation)

$\tilde{Q}x$  where  $\tilde{Q}$  is the solution of the matrix **Lyapunov** equation  $\tilde{Q} = QK^T R K A^{-1} \Gamma$

MPC which transforms an infeasible MPC **optimization** problem into a feasible one. The algorithm

problem using the strategy of lexicographic goal **programming** where the objectives have different

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On Receding Horizon Extensions and Control Lyapunov.. - Primbs, Nevistic, Doyle (1998)  
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On Receding Horizon Extensions and Control **Lyapunov** Functions Part II: A receding horizon

relation to the Hamilton-Jacobi-Bellman (HJB) **optimization** equation. A variation of Sontag's famous CLF

1 positive semi-definite. A standard dynamic **programming** argument reduces the above optimal control

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On Receding Horizon Extensions and Control **Lyapunov** Functions James A. Primbs

Vesna Nevisti'c

stabilizing controller by posing the following **optimization** [3]Pointwise Min-Norm minimize  $u^T u$

,positive semi-definite. A standard dynamic **programming** argument reduces the above optimal control

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On Receding Horizon Extensions and Control **Lyapunov** Functions Part I: Background  
James A. Primbs

feasibility problems and complicate the on line **optimization** [16]On the other hand, obtaining stability

a state feedback control law. A standard dynamic **programming** argument reduces the above optimal control

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Stability Properties Of The Gradient Projection Method With.. - Solodov And (1994)  
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P. Habets, and M Laloy. Stability Theory by **Liapunov's** Direct Method. Springer-Verlag, New York,

follows. In section 2 we outline the Generalized **Lyapunov** Direct Method for stability analysis. In Section

Introduction We consider the following general **optimization** problem  $\min_{x \in X} f(x)$  where  $X$  is a

[ftp.cs.wisc.edu/math-prog/tech-reports/94-05.ps](http://ftp.cs.wisc.edu/math-prog/tech-reports/94-05.ps)

Simultaneous Guaranteed-Cost Vector-Optimal Performance Design for .. - Luke (1999)  
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are equal to the traces of the corresponding **Lyapunov** matrices  $\text{tr}(P_j)$  as  $\lambda_j \in \text{eig}(\Lambda)$

solutions to the problem. A trajectory **optimization** example is given. 1 Introduction The problem

for  $m$  distinct plants is reduced to a convex **programming** problem. Two methods of reducing conservatism

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On the Semi-Definite Programming Solution of the Least Order.. - Mesbahi (1998)  
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All references to stability are in the sense of **Lyapunov**: the origin is the stable equilibrium point of

functional can be optimized. The corresponding **optimization** problem is referred to as semi-definite

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